In the Claims:

1. [previously presented] A method of mobile device control comprising:

moving a surrogate under wireless control by a user;

during the moving, detecting unsuitable degradation of wireless communications of the wireless control; and

in response to the detecting and while the surrogate is still receiving the wireless communications, autonomously moving the surrogate to provide suitable wireless communications of the wireless control.

2. [original] The method as claimed in claim 1 additionally comprising:

autonomously moving the surrogate along a previously determined route.

3. [previously presented] The method as claimed in claim 1 wherein:

autonomously moving the surrogate to provide suitable wireless communications of the wireless control occurs after passage of a period of time following the detecting of the degradation; and

the method further comprises after the detecting of the unsuitable degradation, the surrogate loitering near a location where the unsuitable degradation was detected during the passage of the period of time.

4. [cancelled].

5. [previously presented] The method as claimed in claim 1 wherein:

moving the surrogate under wireless control includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof.

6. [previously presented] The method as claimed in claim 1 wherein:

autonomously moving the surrogate uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement.

7. [previously presented] A method of mobile telepresencing comprising:

moving a surrogate under real-time wireless control by a user;

autonomously moving the surrogate to an area with adequate wireless coverage to regain wireless control when the wireless control is lost for a period of time; and

while the surrogate is autonomously moving, activating a human perceptible indicator which is perceptible to humans in the presence of the surrogate.

8. [cancelled].

9. [original] The method as claimed in claim 7 wherein:

losing wireless control includes degradation of the control to a threshold level;

autonomously moving the surrogate to regain wireless control occurs after a period of time.

10. [currently amended] The method as claimed in claim 7 wherein:

autonomously moving the surrogate includes:

backtracking while measuring distance and avoiding collisions by the surrogate;

stopping the surrogate for an obstacle; and

~~automatically without user intervention~~ resuming backtracking after removal of the obstacle.

11. [cancelled].

12. [previously presented] The method as claimed in claim 7 wherein:

autonomously moving the surrogate to backtrack uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof;

autonomously moving the surrogate to backtrack uses a slower speed than forward speed; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

13. [currently amended] A mobile device control system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system on the surrogate for ~~detecting loss of the wireless control, configuring the surrogate to loiter for a non-zero amount of time following the loss of the wireless control near a location at which the loss of the wireless control was detected, monitoring for return of the wireless control during the non-zero amount of time, and~~ moving the surrogate to regain wireless control independently of the wireless control after passage of ~~the~~ a non-zero amount of time following ~~the~~ loss of the wireless control.

14. [cancelled].

15. [previously presented] The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate to regain wireless control occurs after the surrogate remains stationary for the non-zero amount of time.

16. [original] The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate includes measuring distance and avoiding collisions by the surrogate.

17. [cancelled].

18. [previously presented] The system as claimed in claim 13 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof; and

the computer/transceiver system calculates waypoints back along a forward movement path for backtracking movement.

19. [currently amended] A mobile telepresencing system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system for determining when the wireless control is lost and responsive to the determining, autonomously moving the surrogate to an area not currently receiving adequate coverage of the wireless control, but in which the surrogate previously experienced adequate coverage of the wireless control to regain adequate coverage of the wireless control~~, and loitering in the area for the wireless control to return~~.

20. [original] The system as claimed in claim 19 additionally comprising:

the computer/transceiver system for autonomously moving the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

21. [original] The system as claimed in claim 19 wherein:

the computer/transceiver system for determining degradation of the wireless control to a threshold level;

the computer/transceiver system for autonomously moving the surrogate to regain wireless control occurs after a period of time.

22. [currently amended] The system as claimed in claim 19 wherein:

the computer/transceiver system for autonomously moving the surrogate includes:

backtracking means for measuring distance and avoiding collisions by the surrogate during backtracking;

stopping means for stopping the surrogate for an obstacle; and

means for ~~automatically without user intervention~~ resuming backtracking after removal of the obstacle.

23. [cancelled].

24. [previously presented] The system as claimed in claim 19 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof for backtracking;

the computer/transceiver system provides a slower speed than forward speed for backtracking by the surrogate; and

the computer/transceiver system uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

25. [previously presented] The method as claimed in claim 1 wherein:

the detecting comprises comparing a performance parameter associated with the wireless communications with a threshold.

26. [previously presented] The method as claimed in claim 25 wherein:

the detecting comprises determining that a current non-zero data rate at which the surrogate is successfully transmitting data via the wireless communications is less than a desired data rate.

27. [previously presented] The method as claimed in claim 26 further comprising:

prior to the detecting, wirelessly transmitting a video signal at or above the desired rate from the surrogate to the user.

28. [previously presented] The method as claimed in claim 10 further comprising:

prior to the resuming of the backtracking, sensing removal of the obstacle; and

wherein the resuming is responsive to the sensing.

29. [previously presented] The method as claimed in claim 25 wherein the detecting comprises determining that a current transmission delay associated with packets received by the surrogate is greater than an acceptable transmission delay.

30. [previously presented] The system of claim 13 wherein the computer/transceiver system is configured to configure the surrogate to remain stationary near the location for the non-zero amount of time following the loss of the wireless control.

31. [previously presented] The method of claim 7 wherein the surrogate comprises the human perceptible indicator.

32. [new] The system of claim 13 wherein the computer/transceiver system is configured to detect loss of the wireless control, configure the surrogate to loiter for the non-zero amount of time following the loss of the wireless control near a location at which the loss of the wireless control was detected, and monitor for return of the wireless control during the non-zero amount of time.

33. [new] The system of claim 19 wherein the computer/transceiver system is configured to loiter in the area for the wireless control to return.

34. [new] The method of claim 10 wherein the resuming backtracking comprises automatically without user intervention resuming backtracking.

35. [new] The system of claim 22 wherein the means for resuming backtracking after removal of the obstacle comprises means for automatically without user intervention resuming backtracking after removal of the obstacle.